Fenrir Flight 26:
Video can be found here:

- Front truck cam: https://www.flickr.com/photos/100936386@N02/18691997431/in/dateposted-public/
- Truck launch cam: https://www.flickr.com/photos/100936386@N02/18502122530/in/dateposted-public/
- External cam: https://www.flickr.com/photos/100936386@N02/18500910538/in/dateposted-public/

The goal for this flight was to run an updated attitude tracker to fix the deficiencies noticed in Flight 25. We mapped pilot sticks to provide a pitch and roll angle command (+/- 20 degrees from a 7 degree trim point in pitch and +/-35 degrees in roll). The pilot also had an auto throttle available to hold the aircraft at 23 m/s, which he engaged part way through the test run. The tracking looked very good and the pilot landed in the pitch / roll angle command mode.

Gains for this flight were:

- static double roll_gain[3] = {0.375,0.075,0.01}; // PI gains for roll tracker and roll damper
- static double pitch_gain[3] = {-0.3,-0.40,-0.01}; // PI gains for theta tracker and pitch damper
- static double v_gain[2] = {0.091, 0.020}; // PI gains for speed tracker